

WEST Search History

DATE: Saturday, October 24, 2009

<u>Hide?</u>	<u>Set Name</u>	<u>Query</u>	<u>Hit Count</u>
<i>Prior Art</i>			
<i>DB=USPT; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L98	L97 and "reaction force" and moment	33
<input type="checkbox"/>	L97	dynamic model and L96	40
<input type="checkbox"/>	L96	foot and L92	440
<input type="checkbox"/>	L95	foot and L93	1
<input type="checkbox"/>	L94	float\$4 and L92	161
<input type="checkbox"/>	L93	"0" and L91	1
<input type="checkbox"/>	L92	robot\$6 and L90	2037
<input type="checkbox"/>	L91	L89 and zmp (700/245 l700/246 l700/251 l700/253 l700/260 l700/261 318/568.1 l	1
<input type="checkbox"/>	L90	318/568.12 l318/568.16 l318/568.17 l318/568.2 901/1 l901/9 l901/46 180.1).ccls.	2343
<input type="checkbox"/>	L89	(("6962220")!.PN.) .p67-p150.	1
<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L88	robot\$6 and (walk\$3 or biped or humanoid or two legged) and (inlina\$6 or betn or tilt or deviat\$5 or obliqu\$5 or indirect\$4 or change direction or slope or slant)	6787
<input type="checkbox"/>	L87	('6711469' l'6697709' l'6567724' l'6505098' l'6493606' l'6480761' l'6330494' l'6289265' l'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	16
<input type="checkbox"/>	L86	marc.xa. and legged and inclination	37
<input type="checkbox"/>	L85	marc.xa. and legged and inclinaiton	0
<input type="checkbox"/>	L84	('5404086')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L83	(edding or updating) and (motion or traject\$4 or movement) and zmp and robot\$6	31
<input type="checkbox"/>	L82	(edding or updating) same (motion or traject\$4 or movement) and zmp and robot\$6	14

<input type="checkbox"/>	L81	(edditing or updating) same (motion or traject\$4 or movement) and L79	3
<input type="checkbox"/>	L80	robot and zmp and yaw	179
<input type="checkbox"/>	L79	marc.xa. and zmp	49
<input type="checkbox"/>	L78	10/181500	3
<input type="checkbox"/>	L77	('6697709' l'6289265' l'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	6
<input type="checkbox"/>	L76	marc.xa. and robot and zmp	49
<input type="checkbox"/>	L75	(motions or movement or displacement) and L73	857
<input type="checkbox"/>	L74	computer and L72	4
<input type="checkbox"/>	L73	record\$3 and L71	1014
<input type="checkbox"/>	L72	(request or command) and L70	4
<input type="checkbox"/>	L71	L66 and L69	2314
<input type="checkbox"/>	L70	execut\$5 and L68	6
<input type="checkbox"/>	L69	run or L66	1457670
<input type="checkbox"/>	L68	(6458772 or 6284156 or 6348461 or 6262044 or 6410586 or 6342245 or 6277877 or 6399557 or 3857856 or 5835892 or 6376445 or 6440911 or 6163111 or 5610305 or 5230889 or 4391489 or 4483594 or 6410749 or 4876009 or 6358945 or 6281227 or 6391397 or 6432994 or 4920120 or 5874378 or 6374641 or 5384779 or 5523998 or 5537098 or 4260406 or 4293439 or 4386503 or 5179438 or 5208607 or 6275216 or 5534261 or 5640119 or 5831440 or 6049212 or 6271251 or 4949326 or 5015815 or 5194938 or 4870247 or 6258470 or 6316465 or 6388989 or 4505827 or 5210848 or 5230070).pn.	100
<input type="checkbox"/>	L67	(similar or "same") function and L65	1
<input type="checkbox"/>	L66	robot and control software and (chang\$3 or replac\$5)	2314
<input type="checkbox"/>	L65	('20050125099')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L64	(10/126774 10/970977 10/935607 10/919172 10/775845 10/732446 10/726597 10/683496 10/637890)	18
<input type="checkbox"/>	L63	(motion or displacement or trajector\$3) and L61	20
<input type="checkbox"/>	L62	(humanoid or two legged robot and human like robot) and zmp and comput\$5	124
<input type="checkbox"/>	L61	zmp and "approximately 0"	20
<i>DB=PGPB,USPT; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L60	(("20060106495")!.PN.).PGPB. (("7119510")!.PN.).USPT.	2
<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>			

□	L59	grasping and L57	7
□	L58	horizontal and vertical and L56	17
□	L57	signal and detection and L55	38
□	L56	distance and L54	17
□	L55	center and L53	46
□	L54	motion and L52	22
□	L53	gravity and L51	49
□	L52	floor reaction and L50	24
□	L51	foot and robot and ground contact and sensor and sole and joint and reaction and force and walk\$3	60

DB=PGPB; PLUR=YES; OP=ADJ

□	L50	L48	27
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DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ

□	L49	10/553278	1
□	L48	L46 and robot	47
□	L47	metatarsophalangeal	594
□	L46	ground and contact and L43	52
□	L45	groung and contact and L43	0
□	L44	sensor and L42	3
□	L43	axis and L41	76
□	L42	soles and L40	3
□	L41	foot and L39	89
□	L40	L38 and coordinate	3
□	L39	position and orientation and L37	89
□	L38	(L9 or L10) and L36	3
□	L37	landed and landing and foot and robot\$6	167
□	L36	landed and landing and foot and footstep and robot\$6	7
□	L35	landed and landing and foot and footstep and (L9 or L10)	3
□	L34	landded and landing and foot and footstep and (L9 or L10)	0
□	L33	landded and landing and foot and footstep and L23	0
□	L32	landded and landing and foot and L30	0

<input type="checkbox"/>	L31	posture and L29	0
<input type="checkbox"/>	L30	gravity and coordinate and L28	1365
<input type="checkbox"/>	L29	estimat\$3 and position and L27	4
<input type="checkbox"/>	L28	dynamics same model and L24	15721
<input type="checkbox"/>	L27	dyanamics and L24	37
<input type="checkbox"/>	L26	dyanamics same model and L24	3
<input type="checkbox"/>	L25	L22 and L23	0
<input type="checkbox"/>	L24	movement or trajectory and L22	2793038
<input type="checkbox"/>	L23	floor and zmp and L9	1
<input type="checkbox"/>	L22	floor and zmp and L20	0
		(5024920 5173382 5490103 5557564 5901829 6201488 6521838 6518503 6695663 6592418 5733819 6027554 6663326 6694847 6685863 4252414 4588518 4561746 4719331 5118090 5434926 5419740 5558196 5527940 5716481).pn.	48
<input type="checkbox"/>	L20	motion pattern and L17	0
<input type="checkbox"/>	L19	motion pattern and stor\$3 and L17	0
<input type="checkbox"/>	L18	freedom and L16	26569
<input type="checkbox"/>	L17	L14 and L15	0
<input type="checkbox"/>	L16	L14 and gait or gate	1331787
		('6580969' '6493606' '6463356' '6289265' '6243623' '5872893' '5841258' '5838130' '5594644' 'EP 1136193A' 'EP 1103451A')!.ABPN1, NRPN,PN,TBAN,WKU.	18
<input type="checkbox"/>	L14	('20030019671' '20020138359' '6591923' '6458011')!.ABPN1, NRPN,PN, TBAN,WKU.	7
<input type="checkbox"/>	L13	(legged robot or pet robot or humanoid near10 robot) motion and pattern	15
<input type="checkbox"/>	L12	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L10	8
		(6252544 6493606 6243623 6289265 5673367 5355064 5455497 5325031 5357433 5594644 6580969 6718231 5504841 5842533 4621333 4633059 4987527 5937398 6064168 6429812 6584377 5259064 5349646 5946041 4540211 4762261 5273296 5616917 5627440 5794621 6059092 6059092 6068201 6456728 6505098 6711469 5402050 5525883 5841258 6463356 4614504 5040626 5343397 5369346 5378969 5644204 5672924 5838130 5872893 6229552).pn.	97

(700/245 | 700/246 | 700/251 | 700/253 | 700/260 | 700/261 or 318/568.1 | 318/568.12 | 318/568.16 | 318/568.17 | 318/568.2 or 901/1 | 901/9 | 901/46 or 180/8.1 | 180/8.6 | 180/65.1 or 701/23 or 320/116 | 320/120 or 446/376 | 446/384).ccls.

L10 6580969.pn. 2
 L8 11/456454 2
 L7 10/511608 1

DB=USPT; PLUR=YES; OP=ADJ

L6 (("6243623" | "5455497")!.PN.).USPT. 2

DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ

L5 takenaka.in. and legged robot and force reaction and sensor and joints and floor 2
 L4 L2 and 2000 11
 L3 L2 and -2000 0
 L2 (6920374 or 7496428 or 7493192 or 7487011 or 7379789 or 7337040 or 7337039 or 7319919 or 7319918 or 7319917 or 730833).pn. 26

DB=PGPB; PLUR=YES; OP=ADJ

L1 10/562168 1

END OF SEARCH HISTORY